

Figure 1.

PRIOR ART

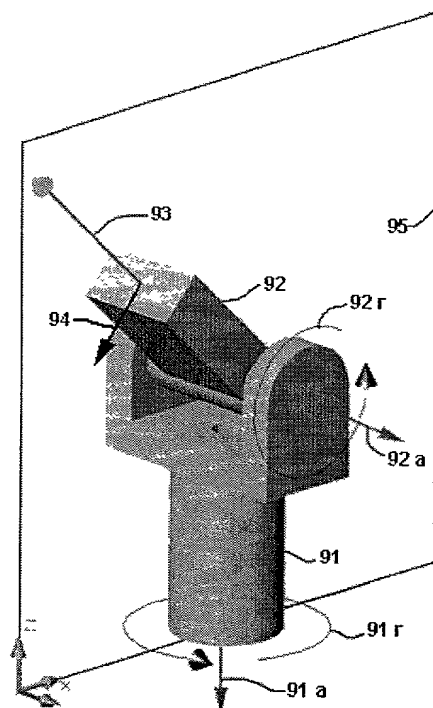


Figure 2

PRIOR ART

2003005050001

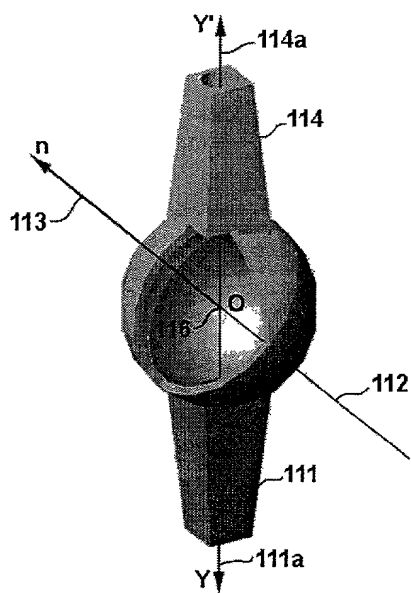


Figure 3a

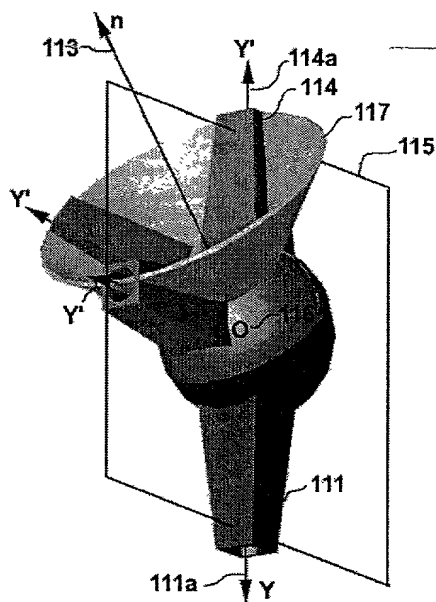


Figure 3b

PRIOR ART

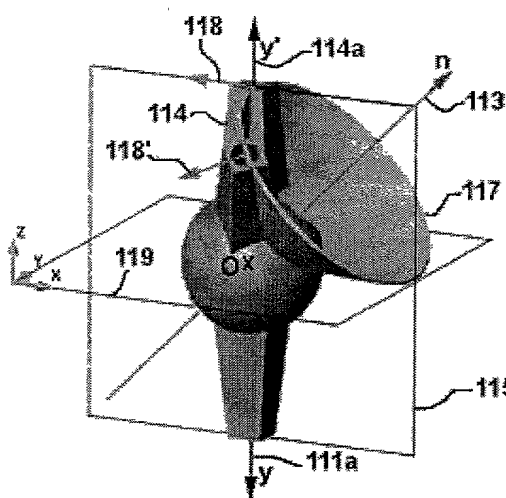


Figure 4a

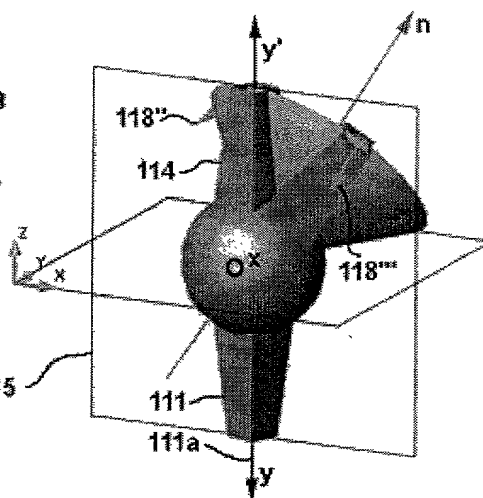


Figure 4b

PRIOR ART

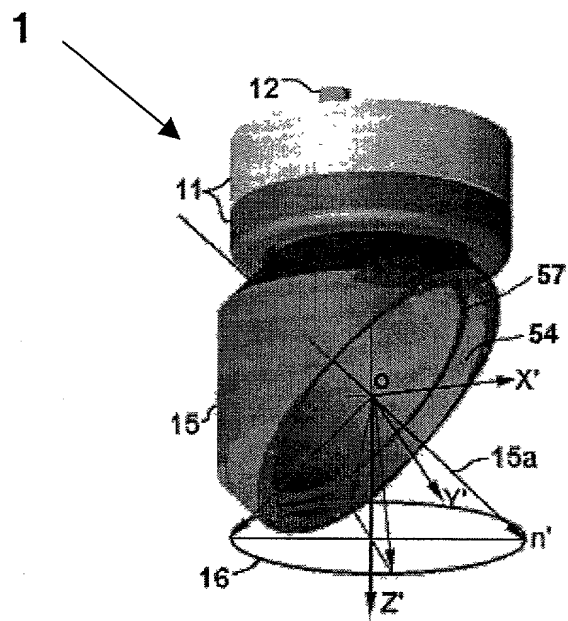


Figure 5a

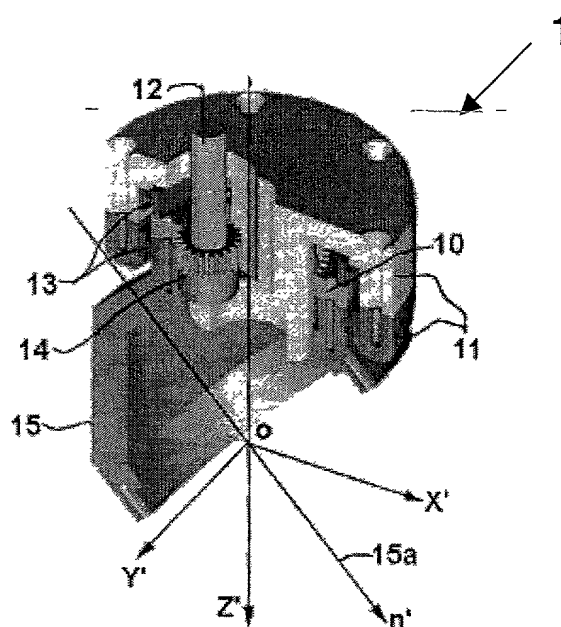


Figure 5b

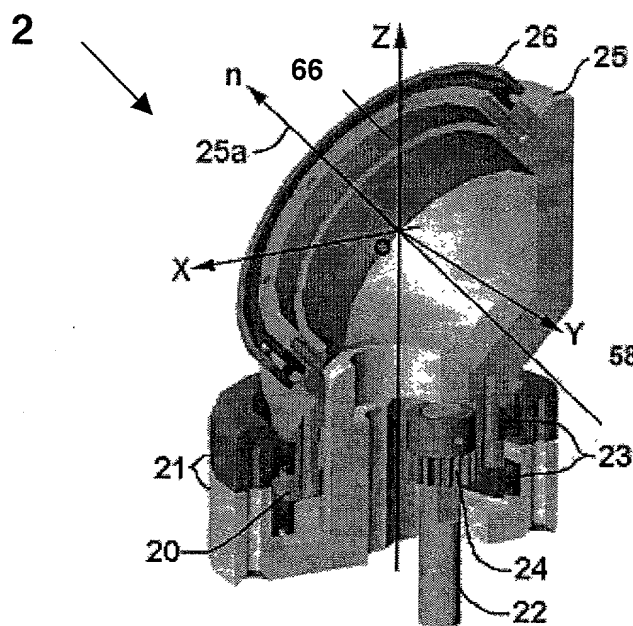


Figure 6a

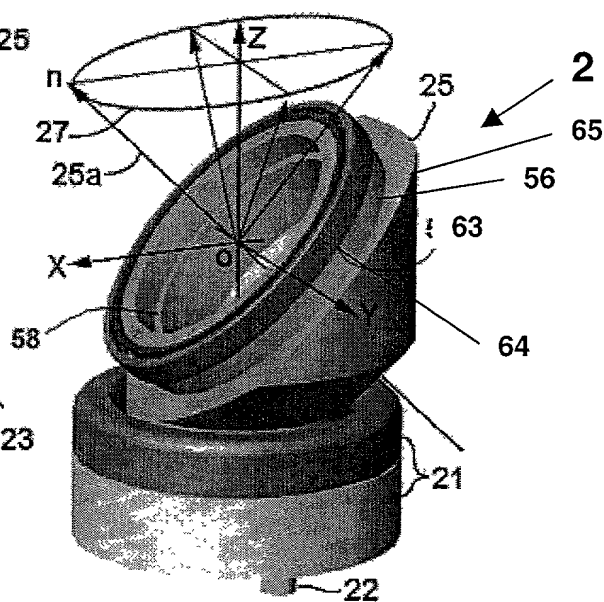


Figure 6b

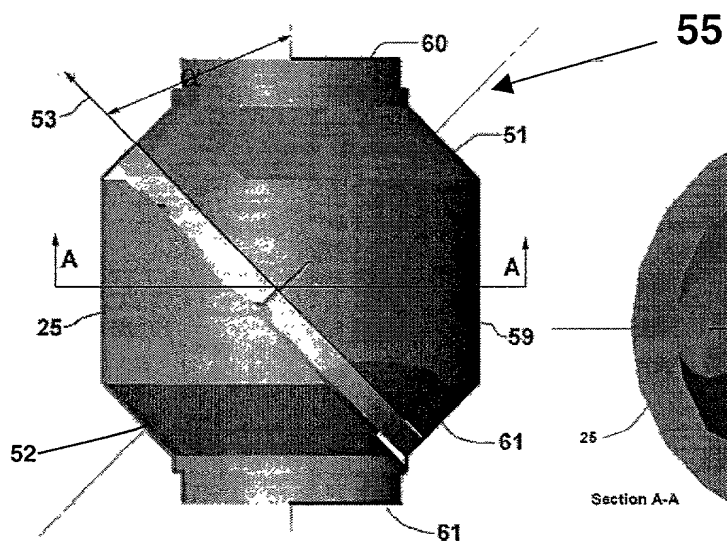


Figure 7a

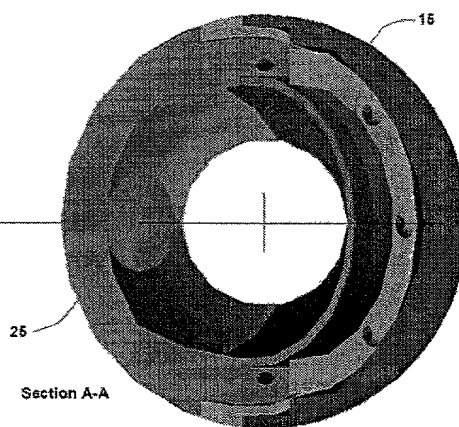


Figure 7b

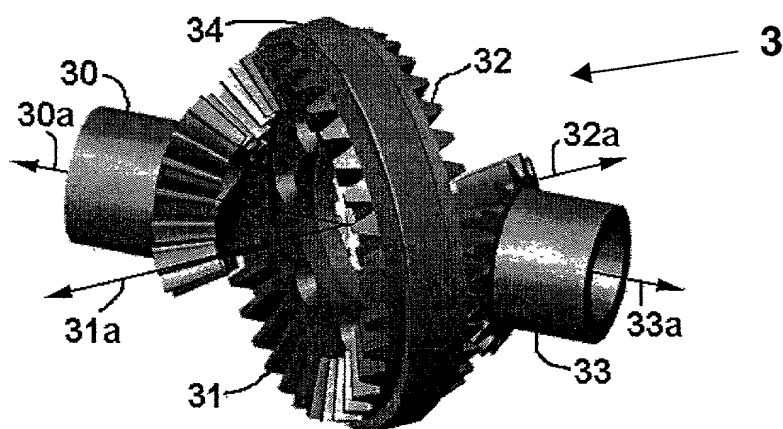


Figure 8

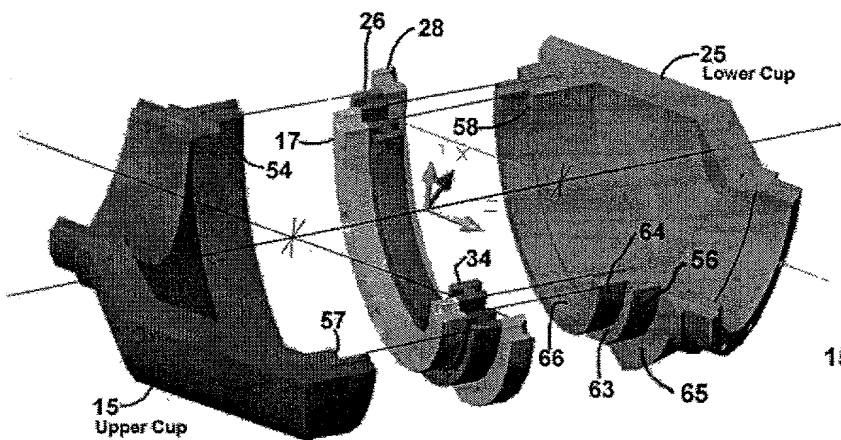


Figure 9a

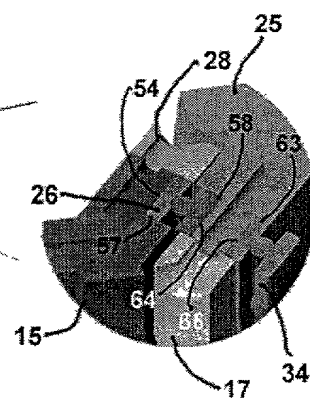


Figure 9b

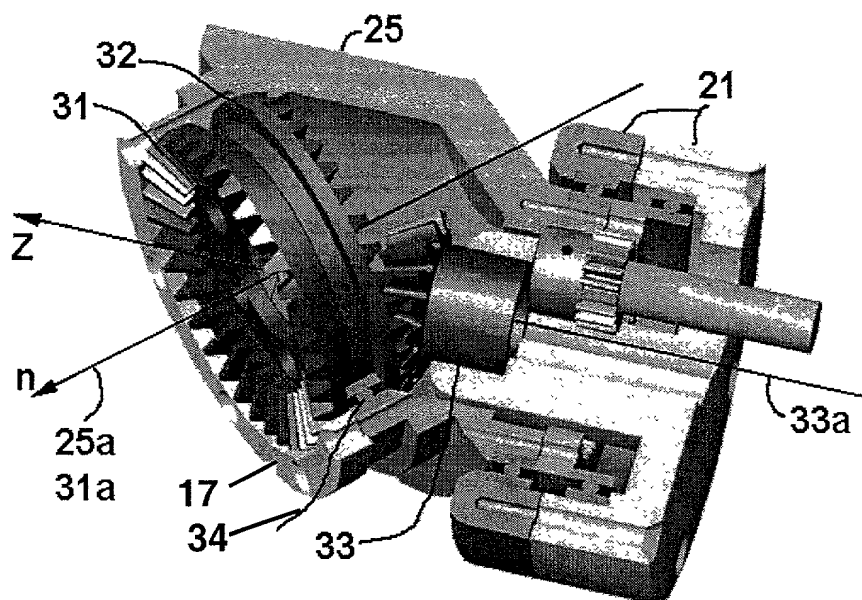


Figure 10

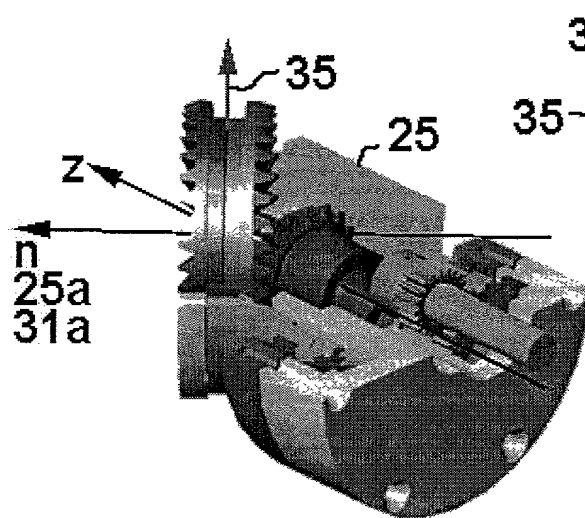


Figure 11a

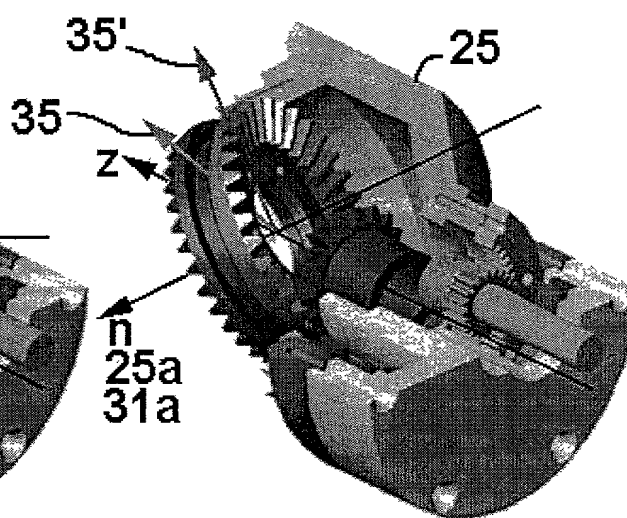


Figure 11b

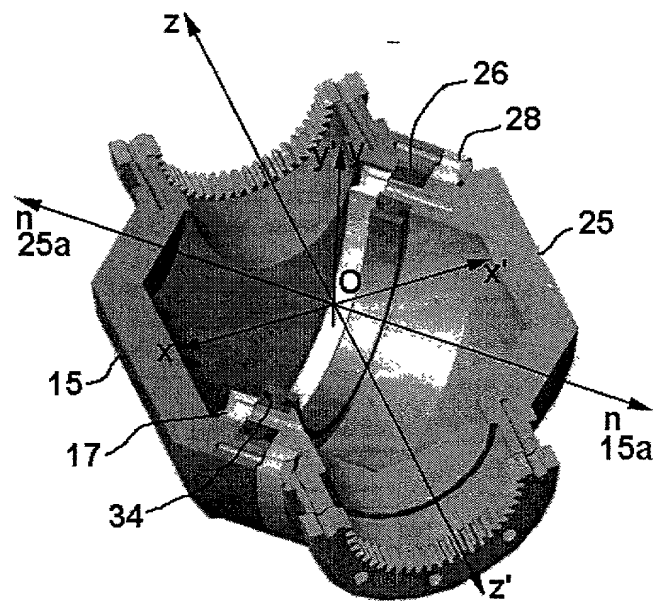


Figure 12

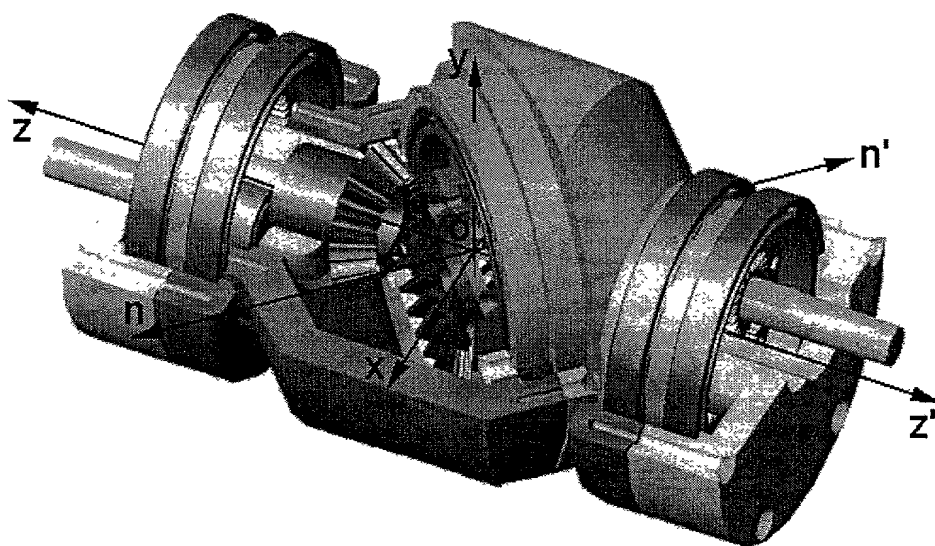


Figure 13

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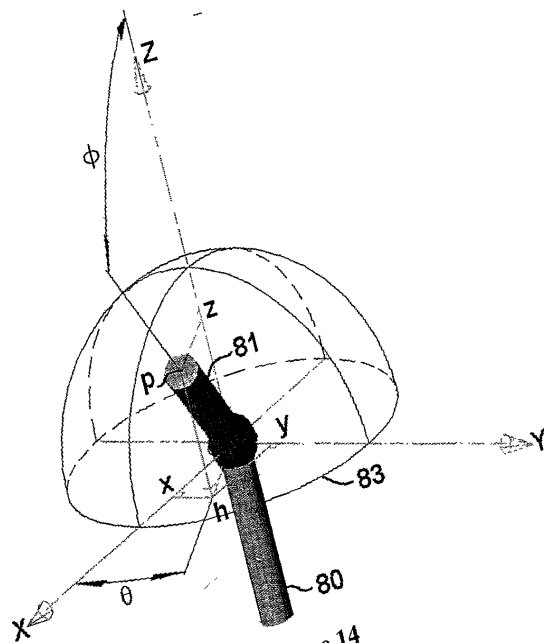


Figure 14

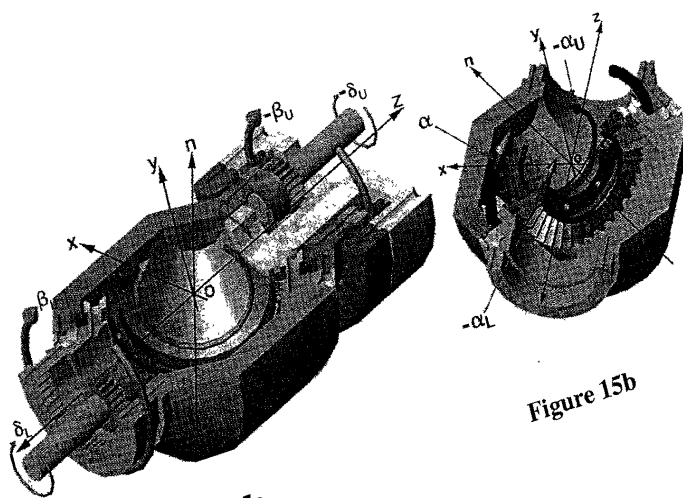


Figure 15a

Figure 15b

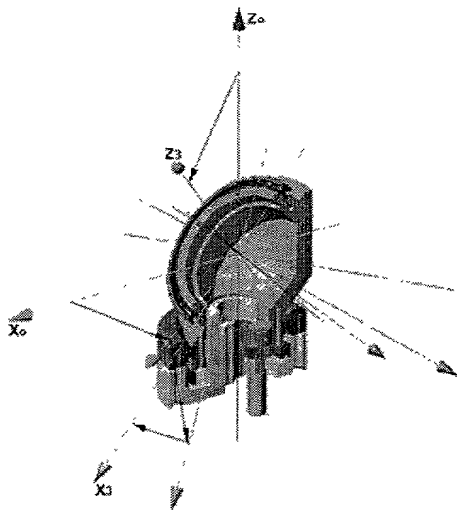


Figure 16a

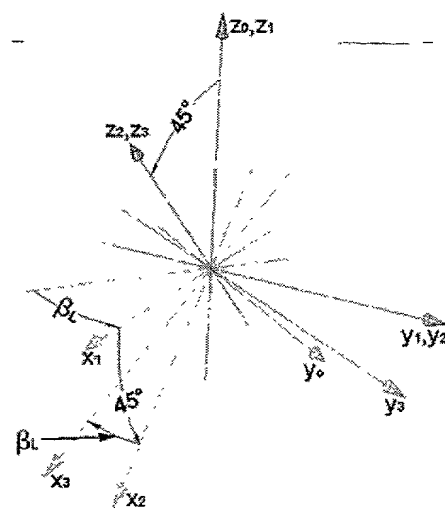


Figure 16b

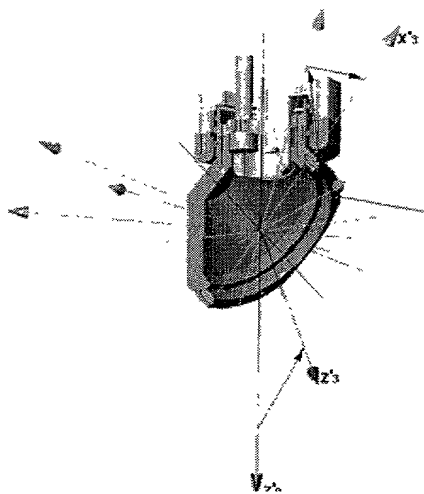


Figure 17a

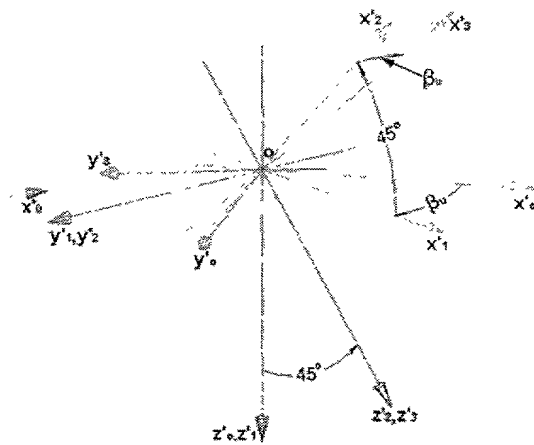


Figure 17b

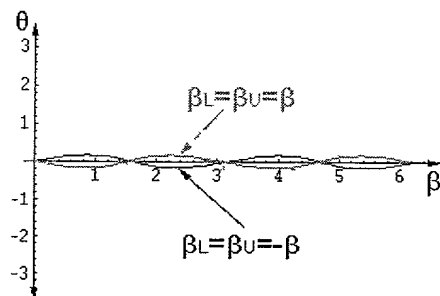


Figure 18a

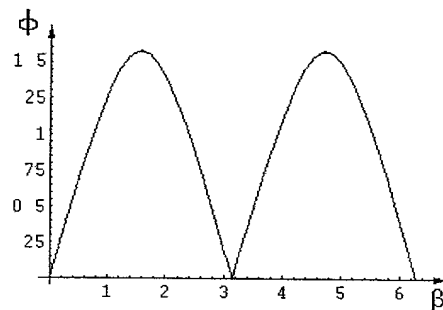


Figure 18b

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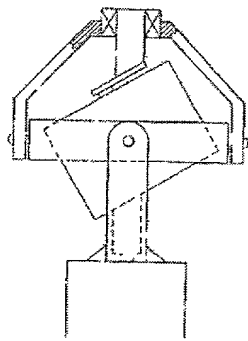


Figure 19a

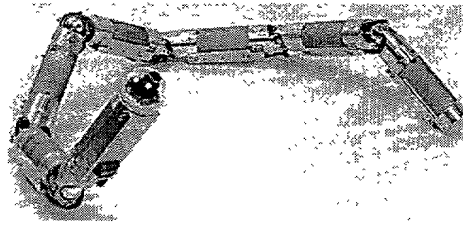


Figure 19b

PRIOR ART

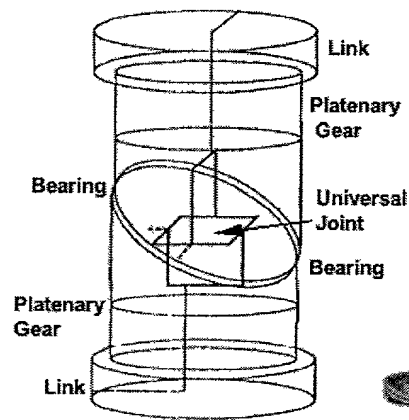


Figure 20a

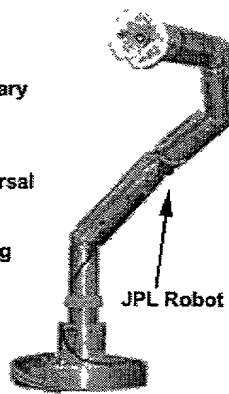


Figure 20b

PRIOR ART

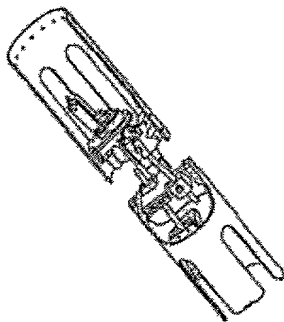


Figure 21a

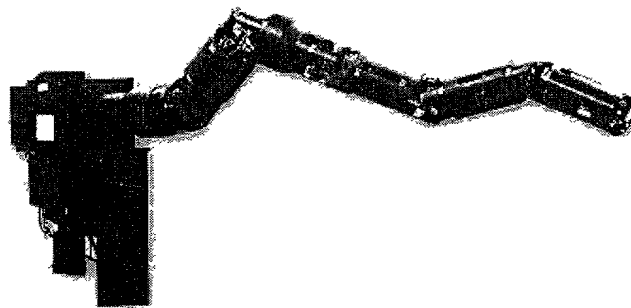


Figure 21b

PRIOR ART

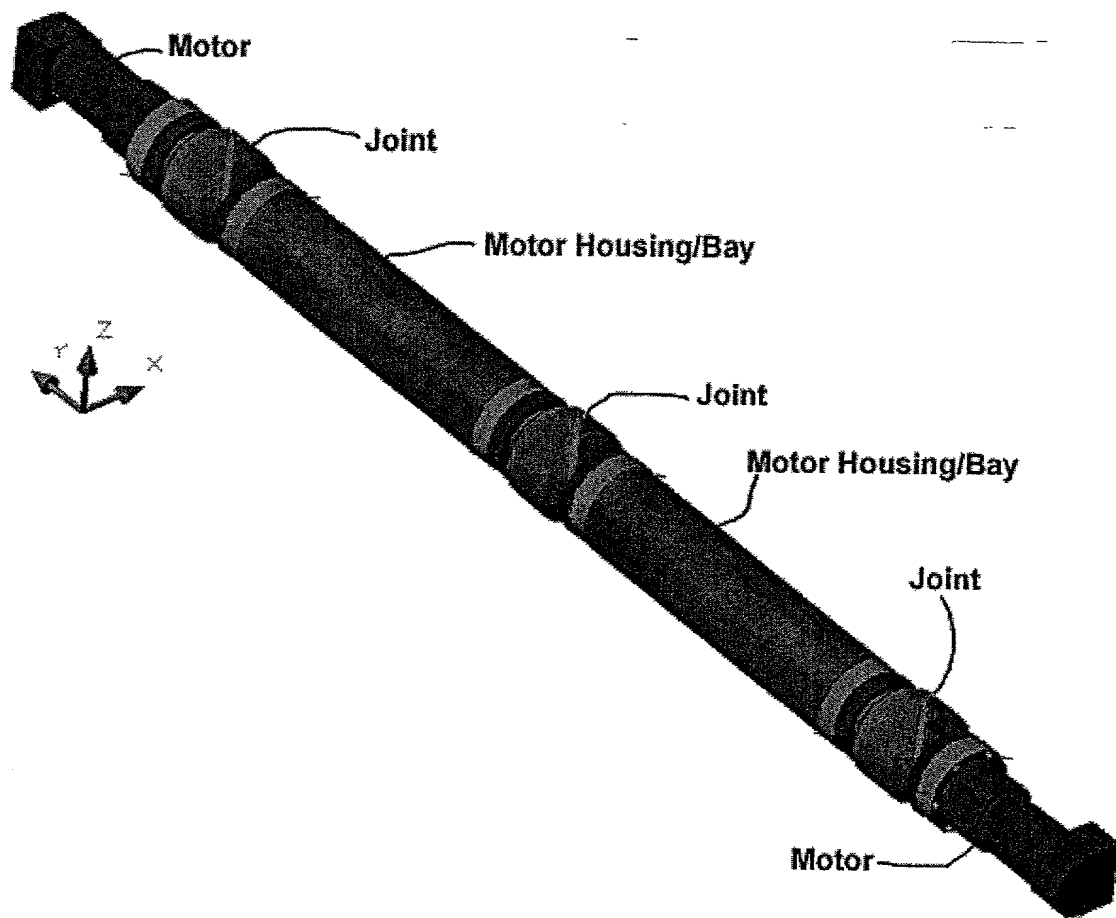


Figure 25.

Figure 25 shows part of a snake robot wherein motor housings / bays are connected together with joints of the present invention.